

FIG. 1 is a schematic diagram of a mechanical linkage system. The system includes a first link 1, a second link 2, a third link 3, a fourth link 4, and a fifth link 5. The first link 1 is connected to the second link 2 at a pivot point 3. The second link 2 is connected to the third link 3 at a pivot point 4. The third link 3 is connected to the fourth link 4 at a pivot point 5. The fourth link 4 is connected to the fifth link 5 at a pivot point 6. The first link 1 is also connected to the fifth link 5 at a pivot point 7. The second link 2 is also connected to the fifth link 5 at a pivot point 8. The third link 3 is also connected to the fifth link 5 at a pivot point 9. The fourth link 4 is also connected to the fifth link 5 at a pivot point 10. The fifth link 5 is also connected to the first link 1 at a pivot point 11. The second link 2 is also connected to the first link 1 at a pivot point 12. The third link 3 is also connected to the first link 1 at a pivot point 13. The fourth link 4 is also connected to the first link 1 at a pivot point 14. The fifth link 5 is also connected to the first link 1 at a pivot point 15.

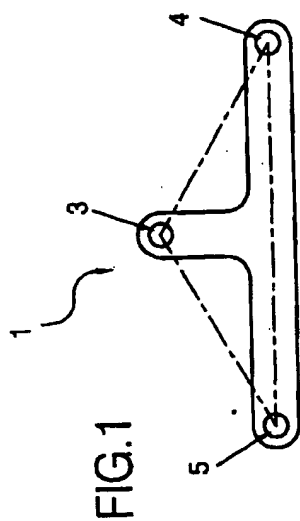


FIG.1

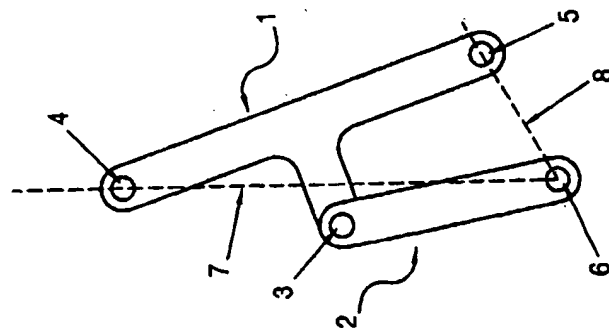


FIG.2

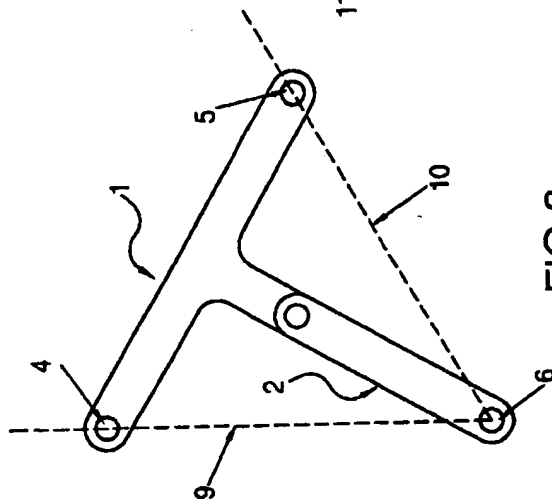


FIG.3

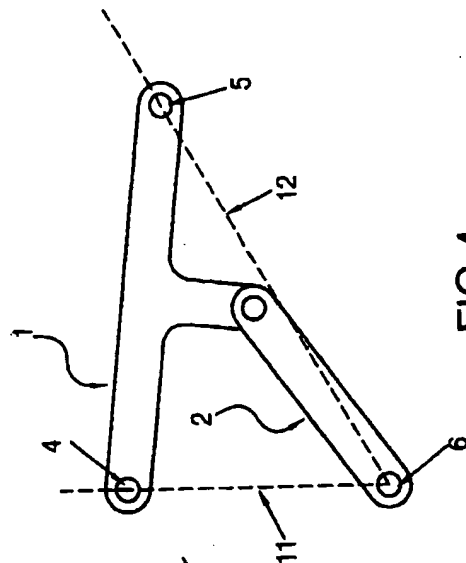


FIG.4

FIG. 5

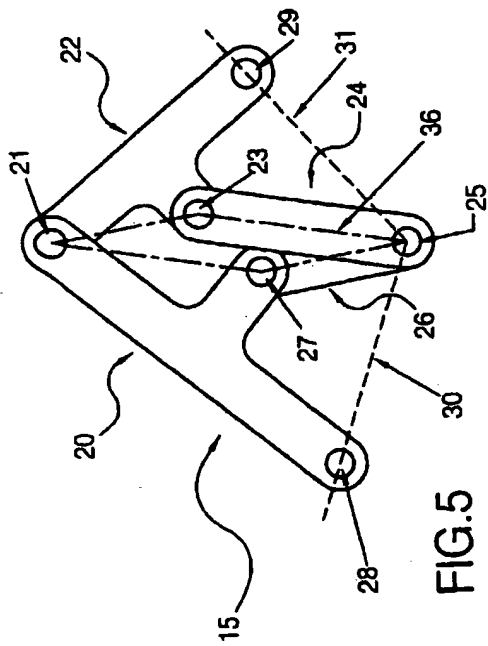


FIG. 5

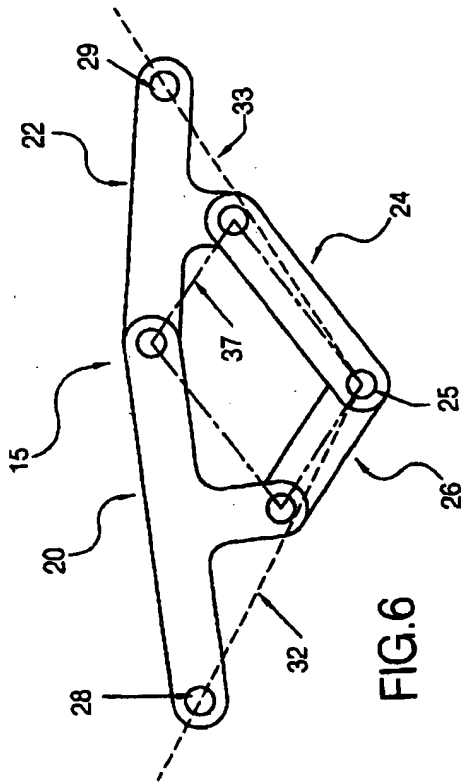


FIG. 6

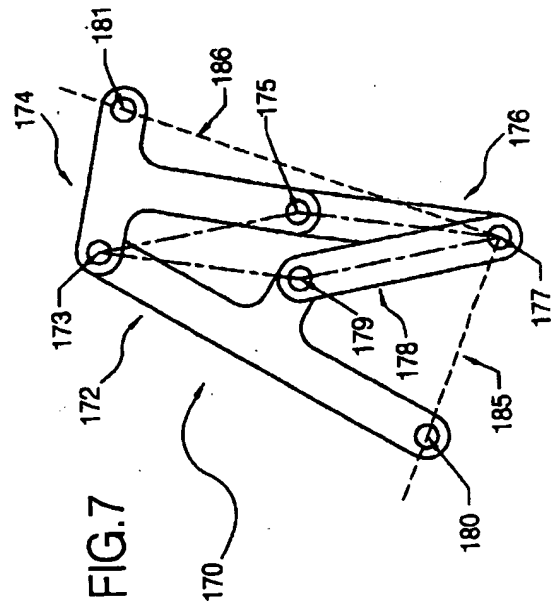


FIG. 7

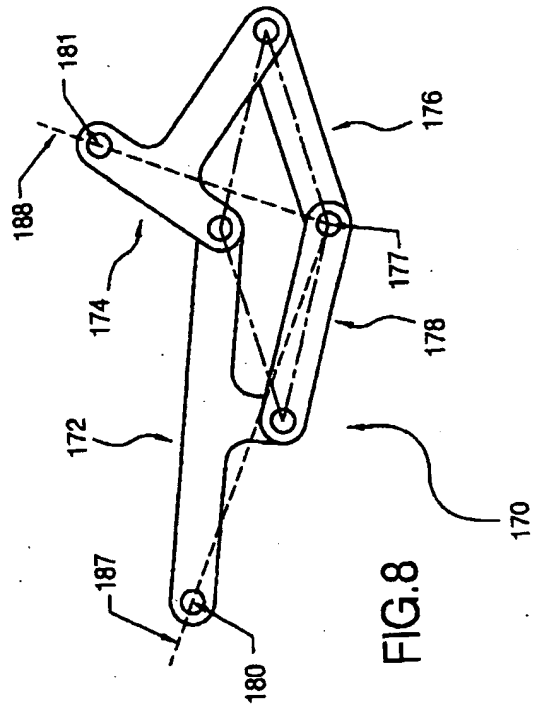
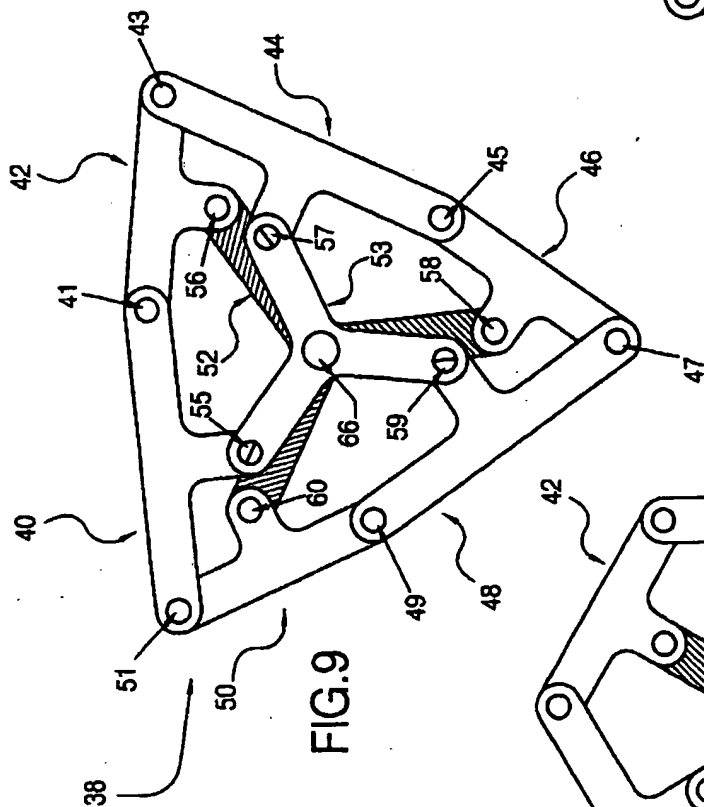
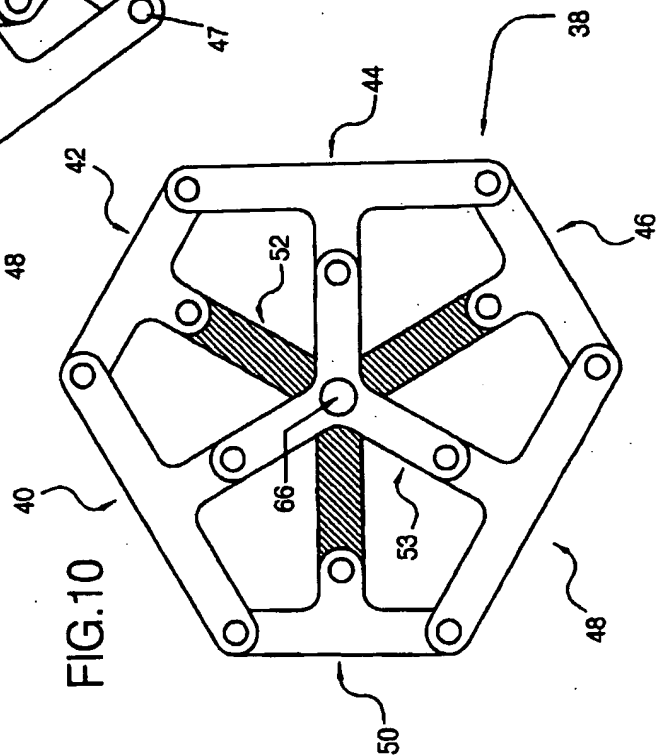


FIG. 8



**FIG. 9**



**FIG. 10**

**FIG. 11**

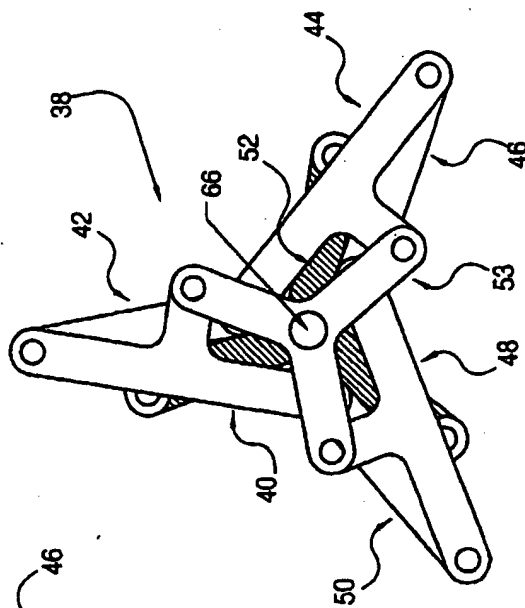
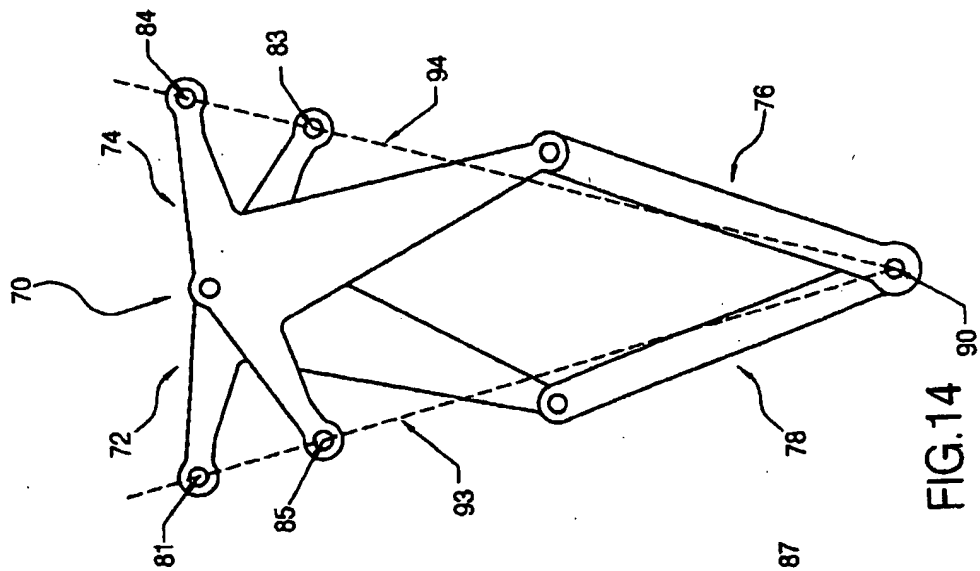
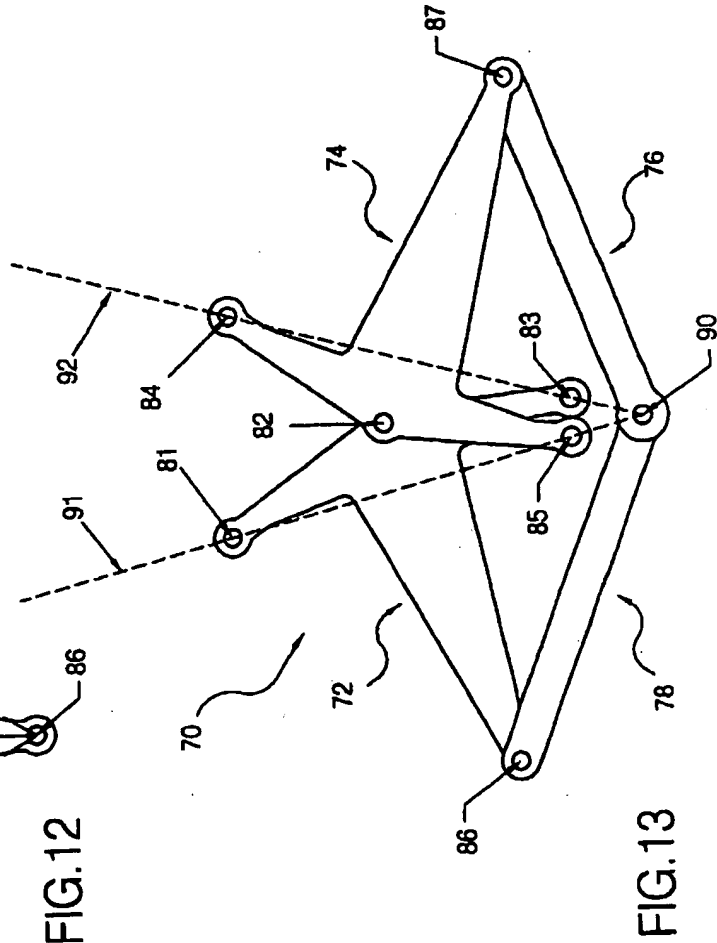
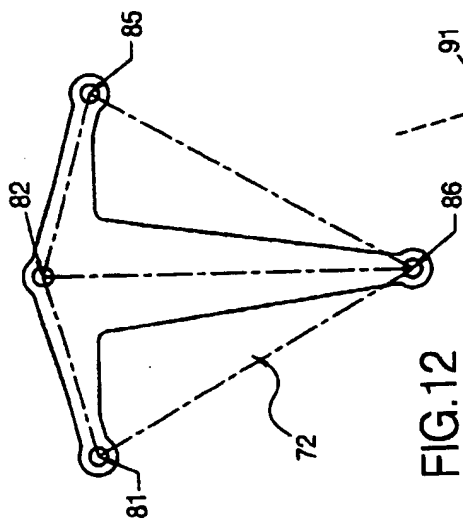


FIG. 12 is a perspective view of the mechanism of FIG. 11, showing the mechanism in a collapsed state. The mechanism is shown in a collapsed state, with the arms 72 and 74 folded together. The pivot points 81, 82, 83, 84, 85, and 86 are clearly visible. The dashed lines indicate the movement of the arms and the pivot points.



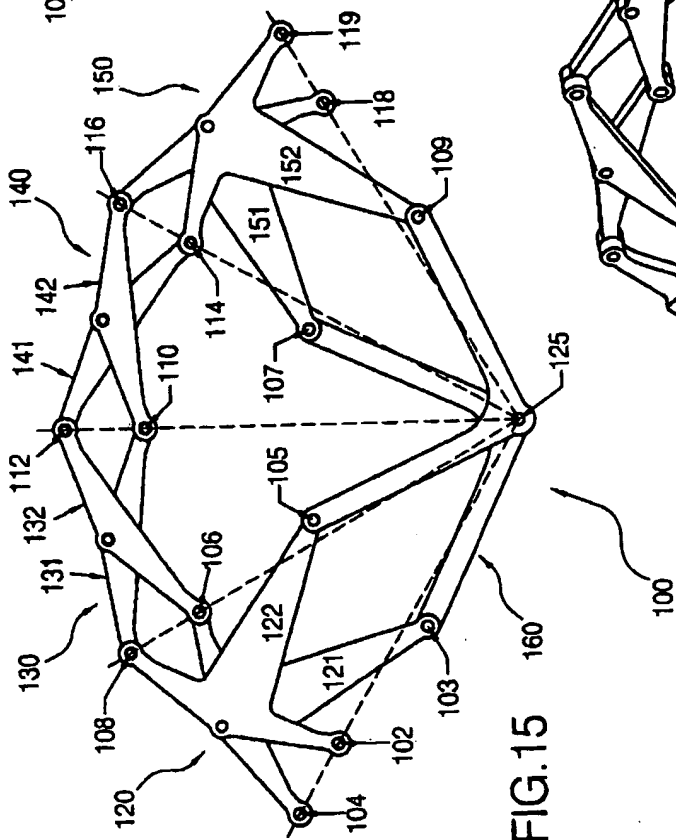


FIG. 15

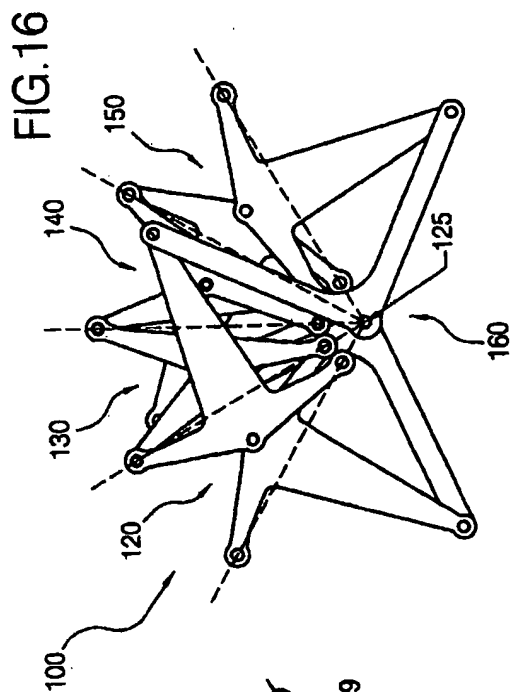


FIG. 16

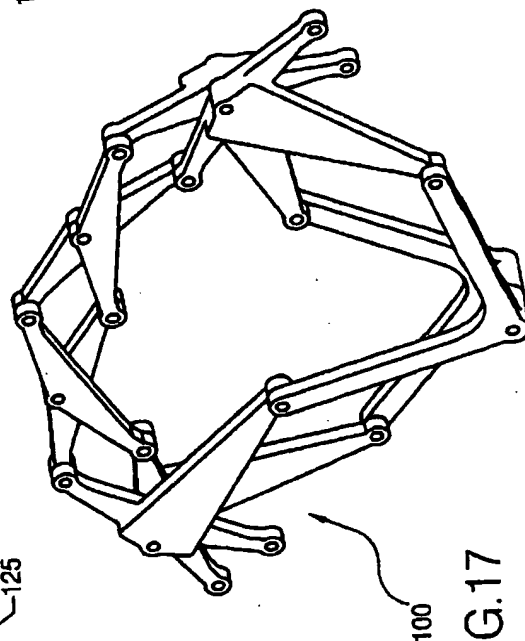


FIG. 17

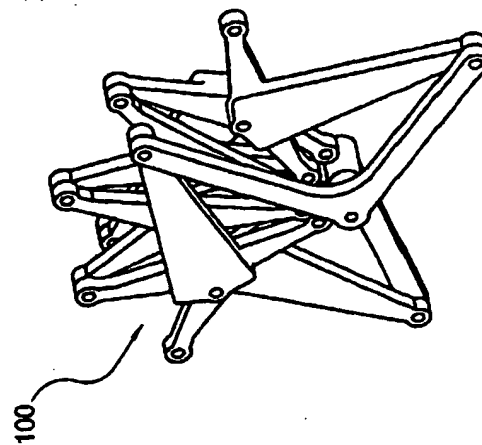


FIG. 18

FIG. 19 is a perspective view of a cage-like structure 200, which is a polyhedron with a central void. The structure is composed of a series of interconnected members 210, 215, 220, 225, 230, 235, 240, 245, 250, 255, 260, 265, 266, 267, and 270. The structure is shown in a perspective view, highlighting its three-dimensional nature and the central void.

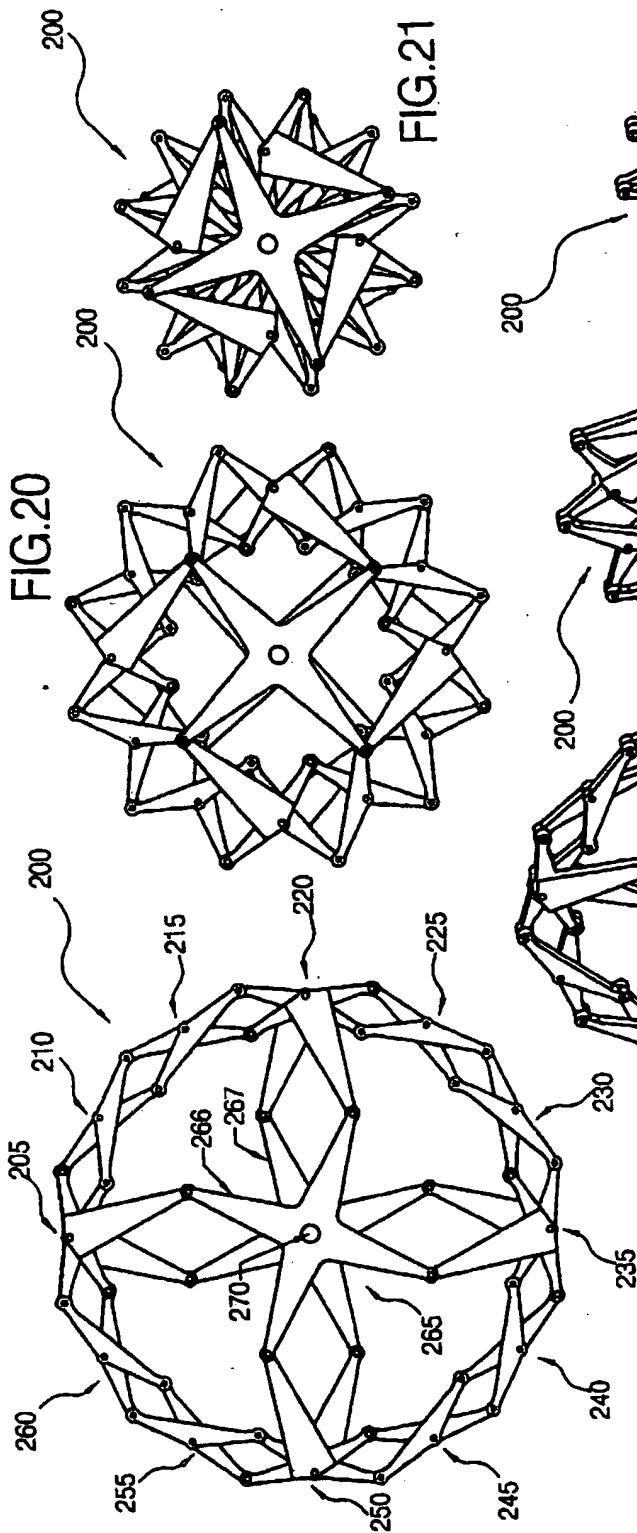


FIG. 19

FIG. 20

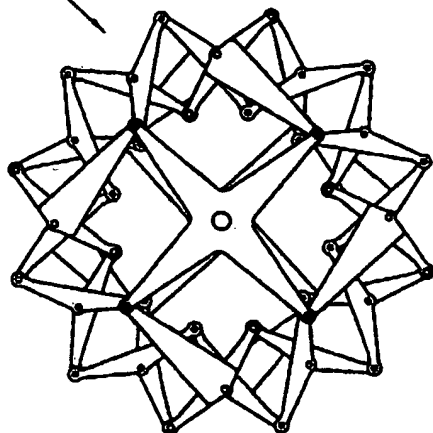


FIG. 21

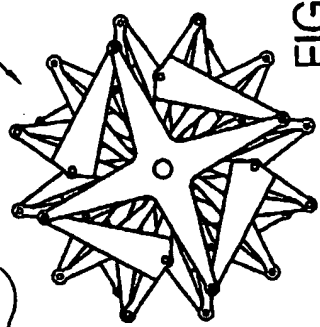


FIG. 22

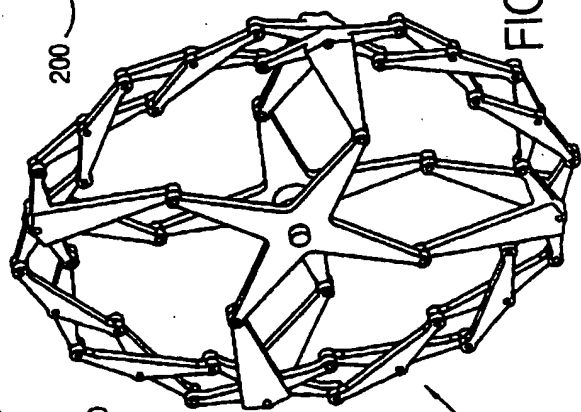


FIG. 23

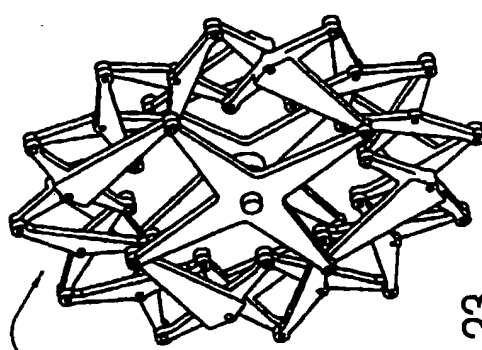
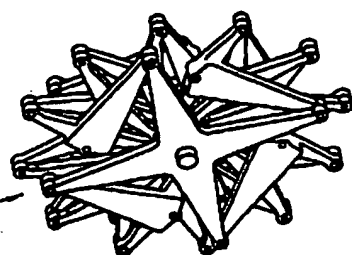


FIG. 24



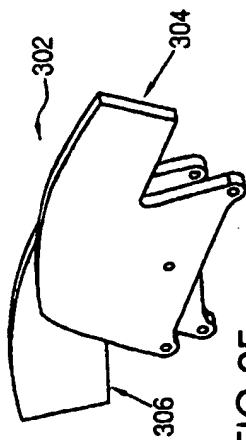
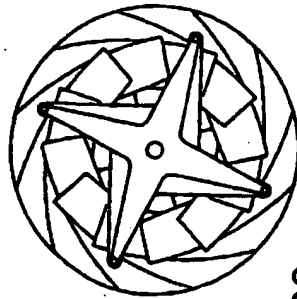
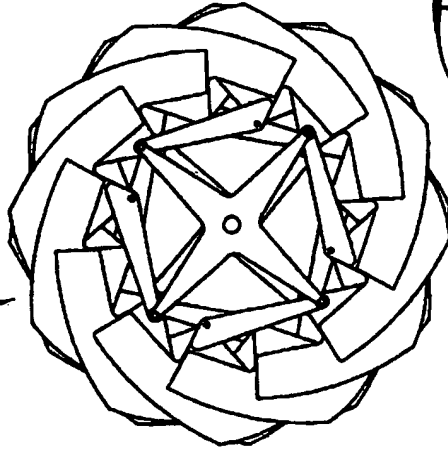


FIG. 25

FIG. 27

300



300

FIG. 26

300

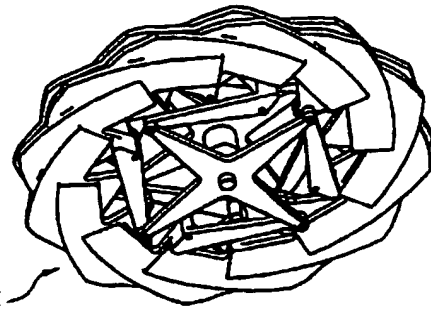


FIG. 30

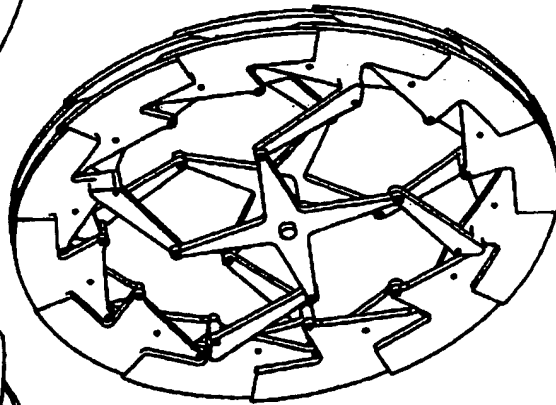


FIG. 31

300

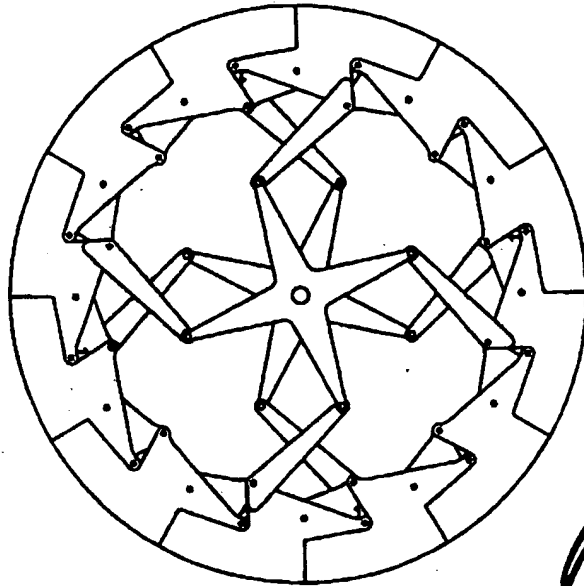


FIG. 28

300

FIG. 29

300

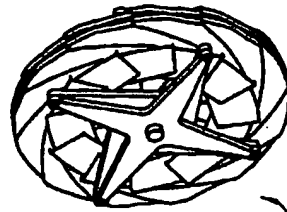


FIG. 32

FIG.32

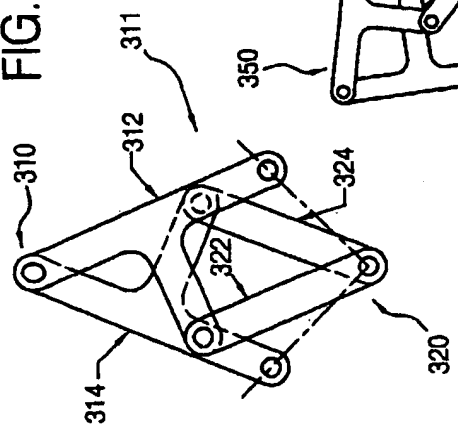


FIG.34

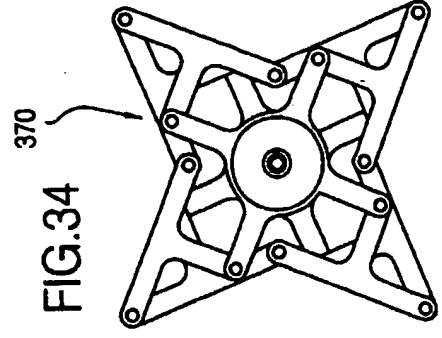


FIG.33

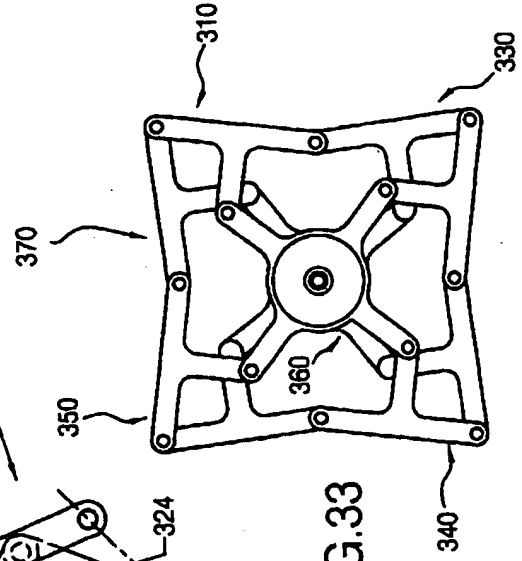


FIG.35

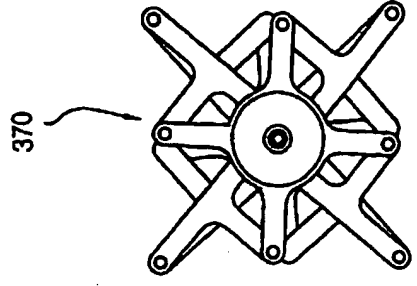


FIG.38

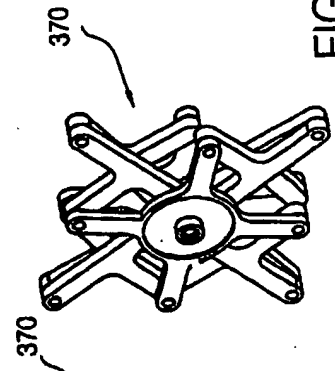


FIG.37

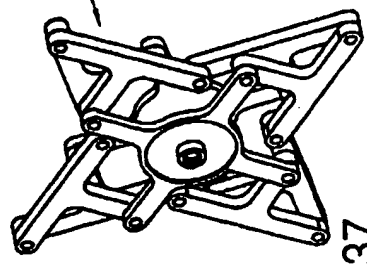


FIG.36

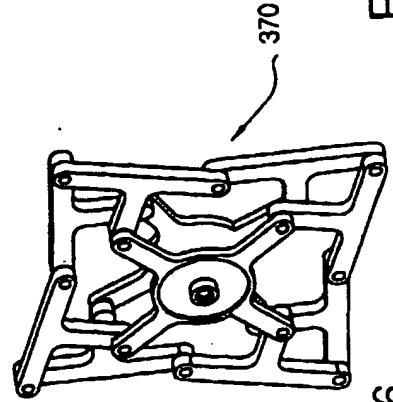




FIG. 39 is a perspective view of the device 100 in a first configuration. The device 100 includes a base 110, a first arm 120, a second arm 130, and a third arm 140. The first arm 120 is connected to the base 110 at a first joint 121. The second arm 130 is connected to the first arm 120 at a second joint 131. The third arm 140 is connected to the second arm 130 at a third joint 141. The device 100 is shown in a first configuration where the first arm 120 is extended horizontally, the second arm 130 is extended vertically, and the third arm 140 is extended horizontally.

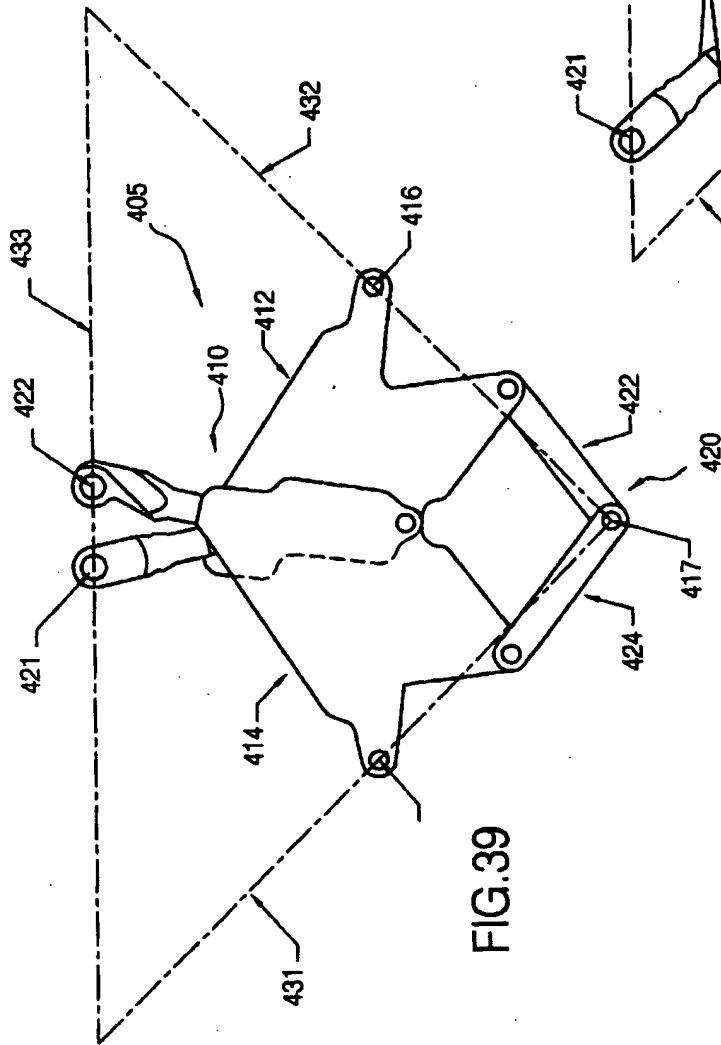


FIG. 39

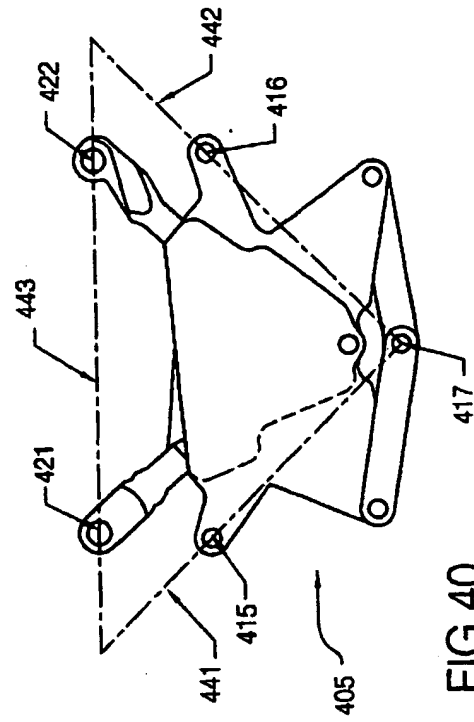


FIG. 40

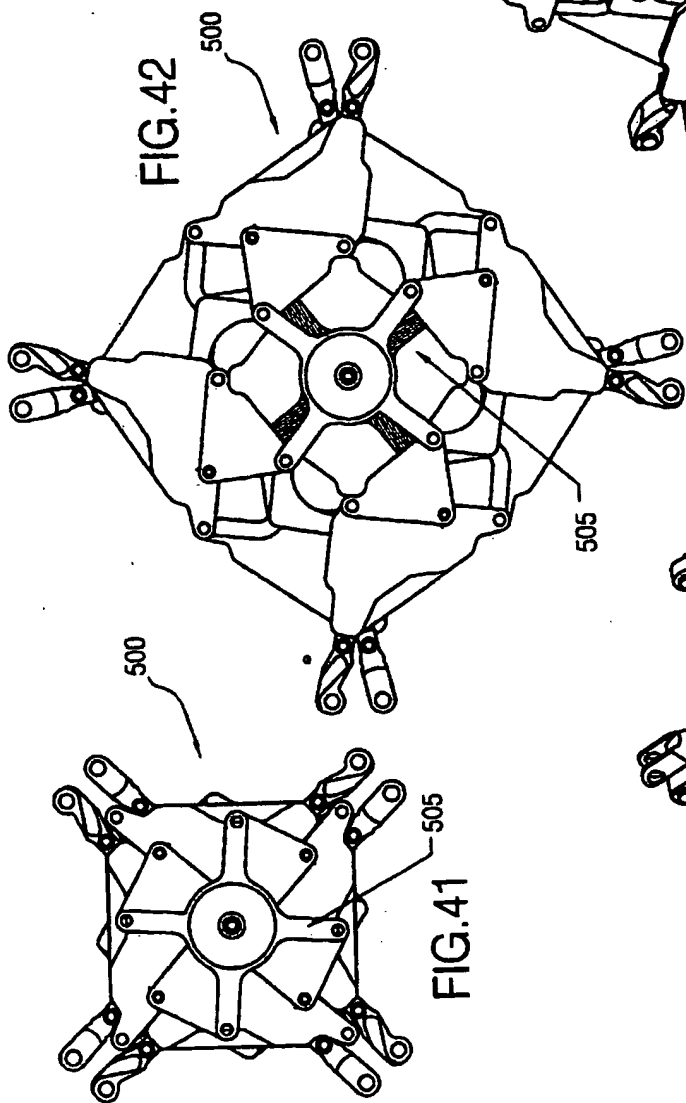


FIG. 42

500

505

500

FIG. 41

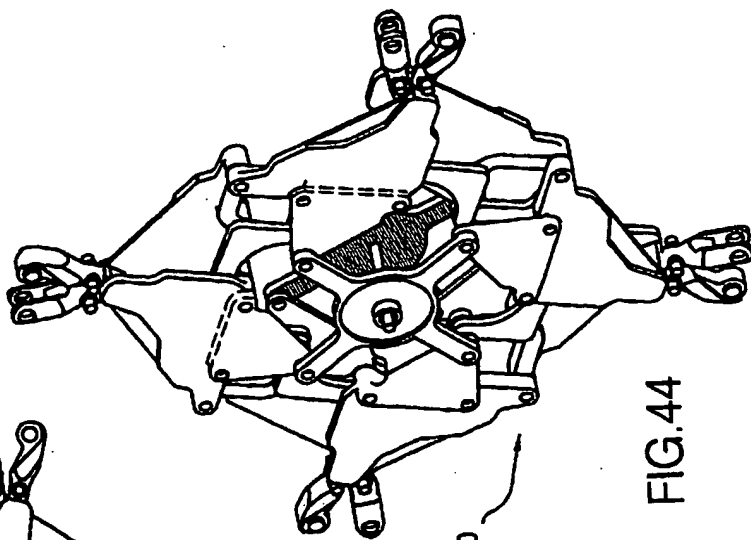


FIG. 44

500

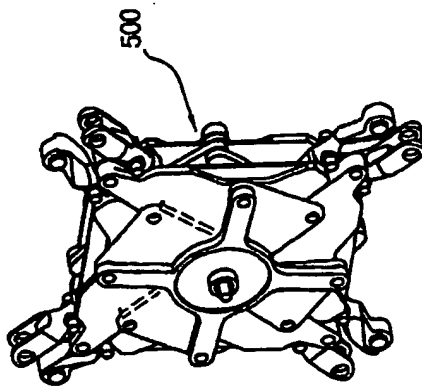


FIG. 43

500

